Tradeoffs in Polarimeter Design

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Report Documentation Page

Form Approved
OMB No. 0704-0188

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1. REPORT DATE	2. REPORT TYPE	3. DATES COVERED
00 MAR 2003	**N/A**	**-**

4. TITLE AND SUBTITLE
Tradeoffs in Polarimeter Design

5a. CONTRACT NUMBER

5b. GRANT NUMBER

5c. PROGRAM ELEMENT NUMBER

6. AUTHOR(S)

5d. PROJECT NUMBER

5e. TASK NUMBER

5f. WORK UNIT NUMBER

7. PERFORMING ORGANIZATION NAME(S) AND ADDRESS(ES)
ECE Department, University of New Mexico Albuquerque, NM 87131-1356

8. PERFORMING ORGANIZATION REPORT NUMBER

9. SPONSORING/MONITORING AGENCY NAME(S) AND ADDRESS(ES)

10. SPONSOR/MONITOR'S ACRONYM(S)

11. SPONSOR/MONITOR'S REPORT NUMBER(S)

12. DISTRIBUTION/AVAILABILITY STATEMENT
Approved for public release, distribution unlimited

13. SUPPLEMENTARY NOTES
See also ADM201529., The original document contains color images.

14. ABSTRACT

15. SUBJECT TERMS

16. SECURITY CLASSIFICATION OF:			17. LIMITATION OF ABSTRACT	18. NUMBER OF PAGES	19a. NAME OF RESPONSIBLE PERSON
a. REPORT	b. ABSTRACT	c. THIS PAGE			
unclassified	**unclassified**	**unclassified**	**SAR**	**38**	

Standard Form 298 (Rev. 8-98)
Prescribed by ANSI Std Z39-18

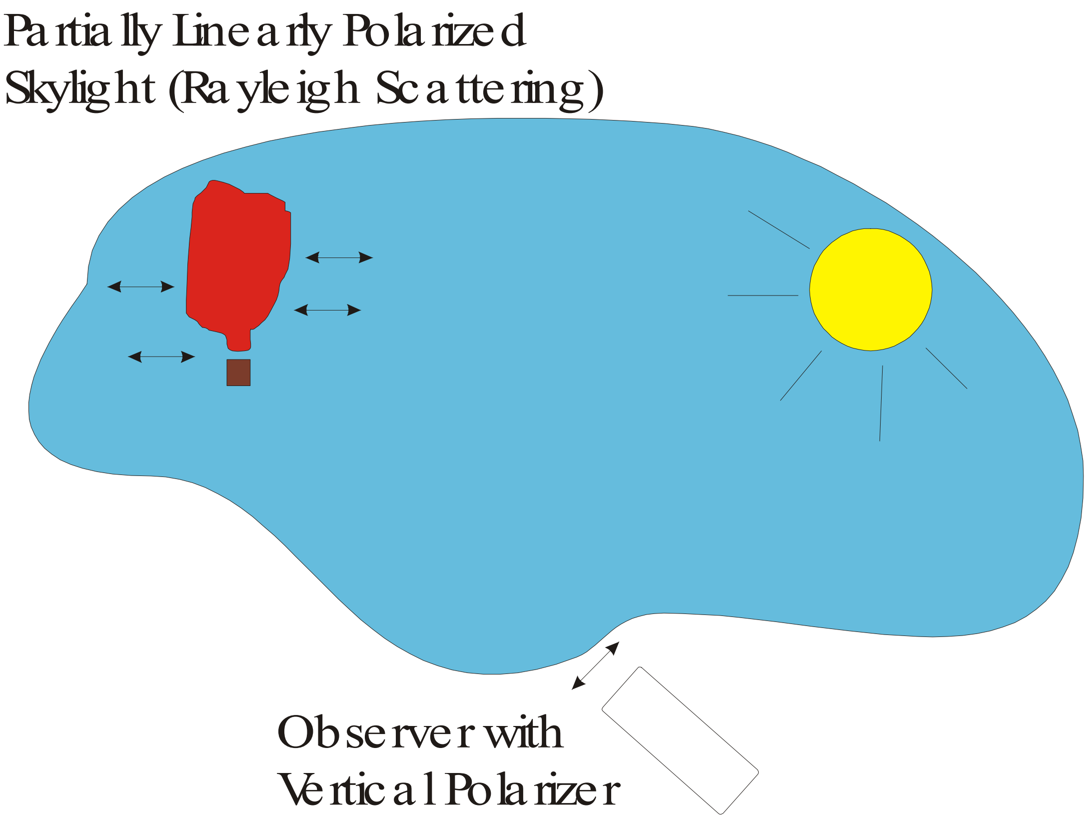
Presentation Outline

- System Dimensionality
  - Example Applications and Methods
- Data Collection Strategies
  - Serial -vs- Parallel
  - Rotating -vs- Non-Rotating Optics
  - Active -vs- Passive
- System Optimization

Multi-Dimensional Stokes Polarimetry

1-D Polarimetry Contrast Enhancement in Photography (e.g. Duntley, 1974; Gilbert, 1964)	**2-D Polarization Difference** Scatter Mitigation, Contrast Enhancement (Tyo, *et al.*,1996; Silverman and Strange, 1996)
3-D Linear Polarimetry Target Identification (Halaijan and Hallock, 1972; Walraven, 1977; Duggin 2002; Wolff, *et al.*, 1994; etc.)	**4-D Stokes Vector Imaging** Target Identification (Soloman, 1981; Chipman, *et al.*, 1997; etc.)

1-D Polarimetry - Photography



- Linear polarization filters are used extensively in photography to maximize the contrast between the subject and the background

- Maximum utility when the scattering background provides a high degree of linear polarization, as when a scattering medium is illuminated at right-angles to the direction of observation

- Beneficial with sky-background, underwater, in fog or dust, etc.

Tradeoffs for 1-D Polarimetry

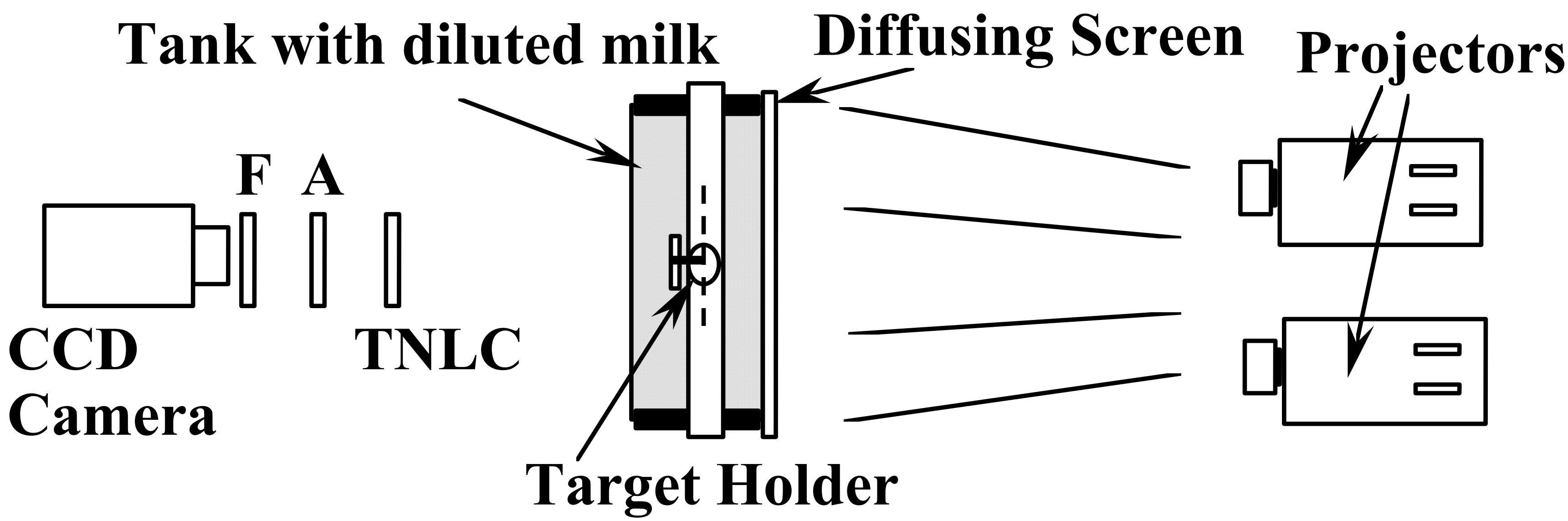
pros

- No images to register
- Can be optimized in near-real time
- Linear or circular

cons

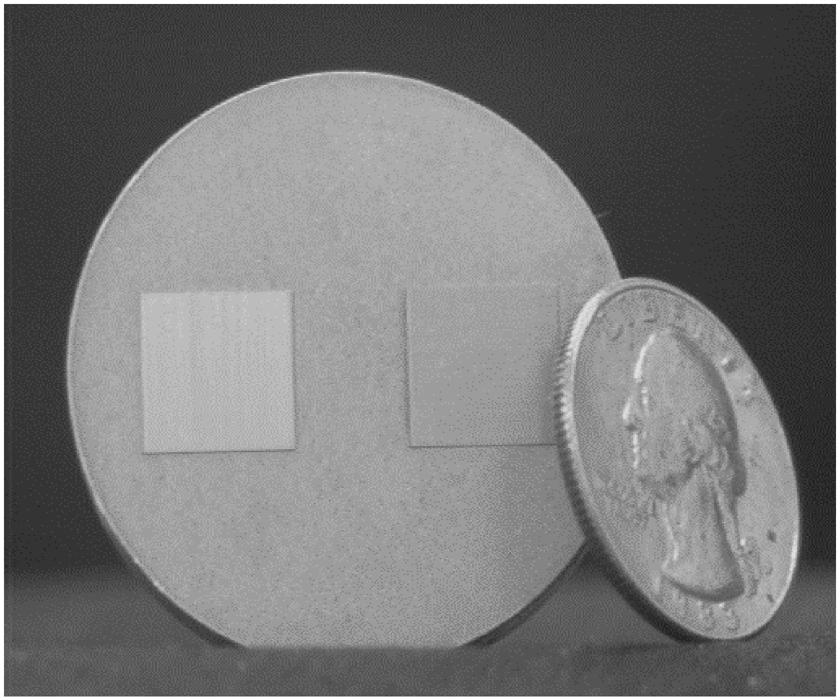
- 3 dimensions of polarization blindness
- Image features vary as system is tuned
- No quantitative polarization result

Experimental Setup for 2-D PDI

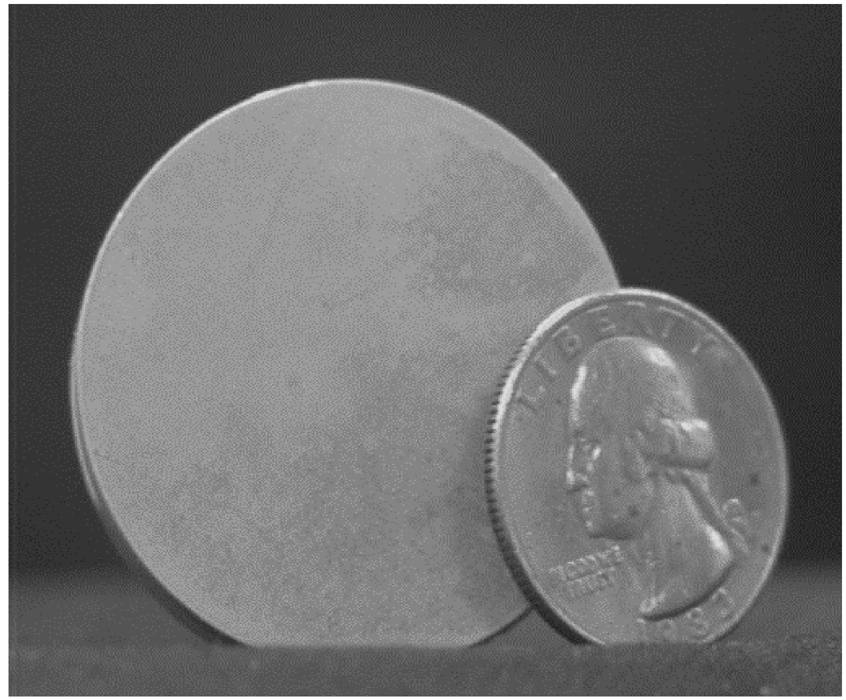


Prepared Targets

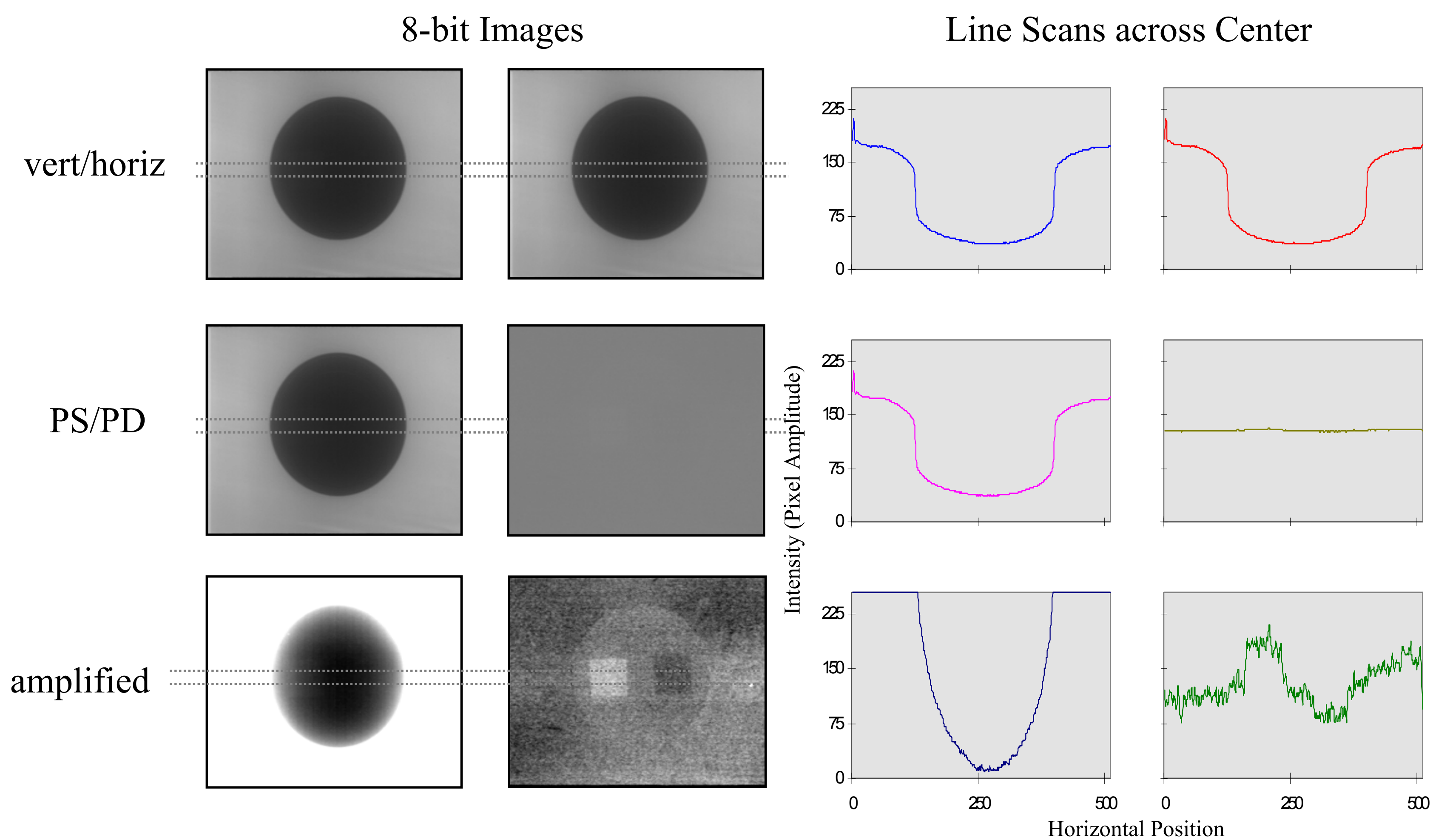
A



B



Step-by-Step PDI (2-D)



Tradeoffs for 2-D Polarimetry

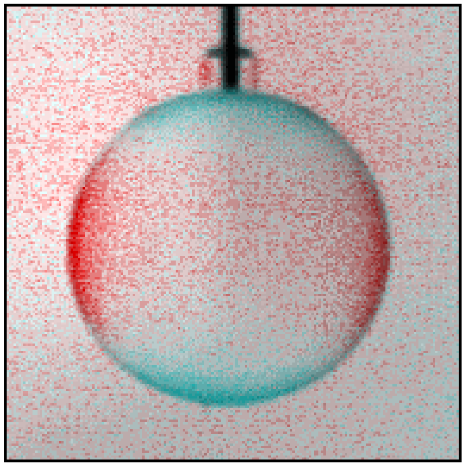
pros

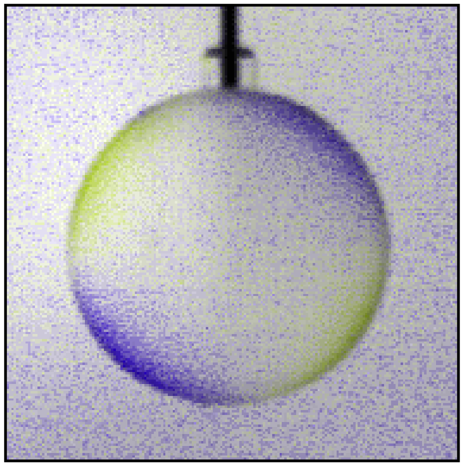
- 2 images to register
- Can be optimized in near-real time
- Linear polarization (can be used with circular too)
- Projects noise into orthogonal dimension, suppresses biases

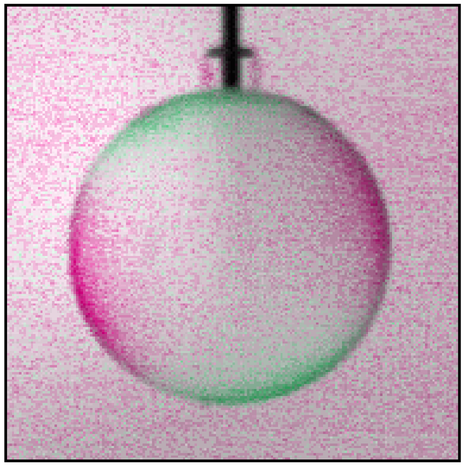
cons

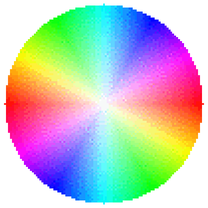
- 2 dimension of polarization blindness
- Image Registration
- Image features vary as system is tuned

2-D Polarization Images

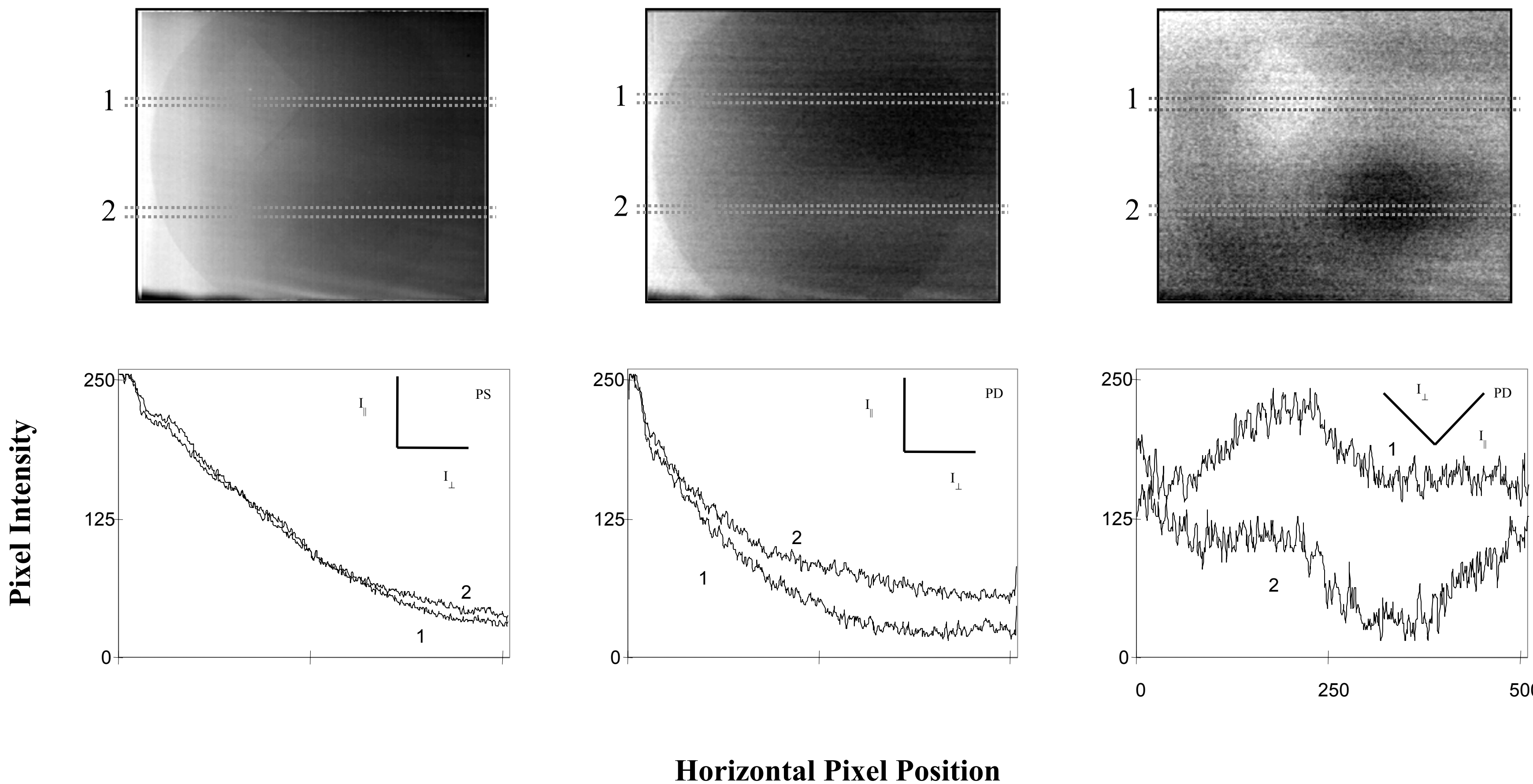




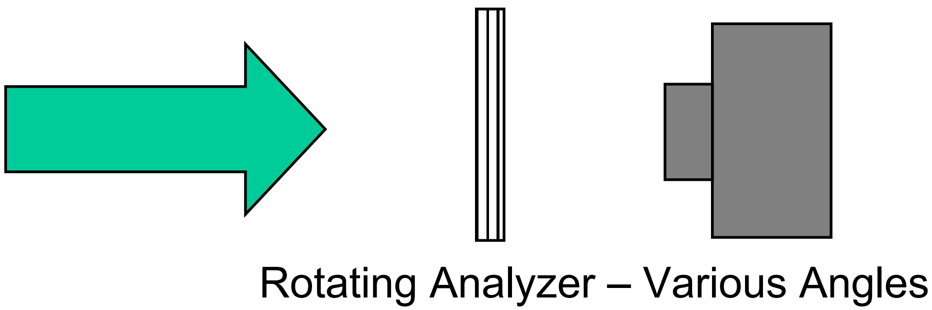




Polarization Bias



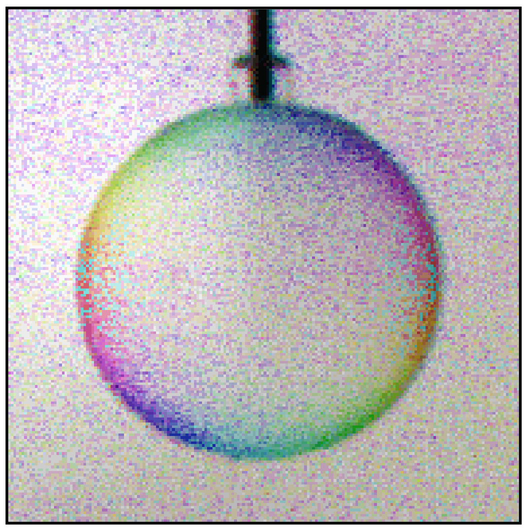
3-D Linear Polarimetry



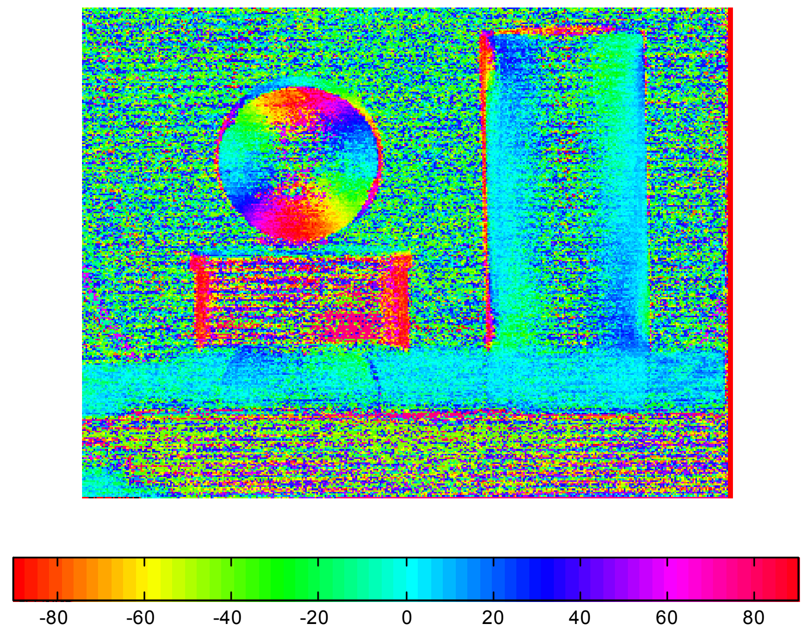
Rotating Analyzer
(2- or 3-D Linear)

- Measures the first three Stokes parameters
- Needs 3 or more measurements
- Can physically or electro-optically rotate

3-D Polarimetric Images



Back-Illuminated dielectric sphere with
full 3-D colorimetric representation



Revisiting the earlier scene
(Note – color axis reversed)

Tradeoffs for 3-D Polarimetry

pros

- Linear polarization (can be used with circular as s_0, s_1, s_3)
- Provides angle of polarization, DOLP

cons

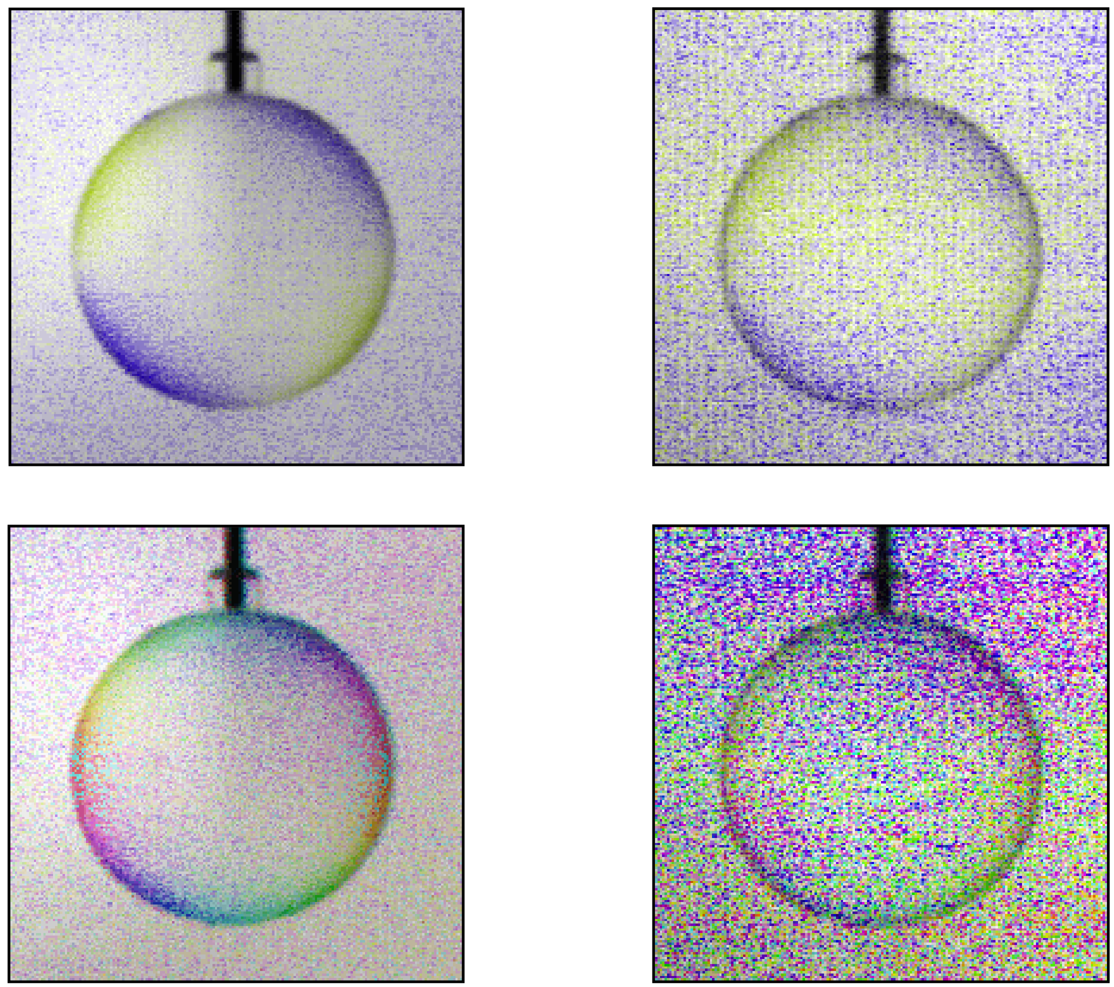
- 1 dimension of polarization blindness
- Image Registration
- Image features vary as system is tuned
- 3-D noise can corrupt data presentation

Benefits of 2-D -vs- 3-D

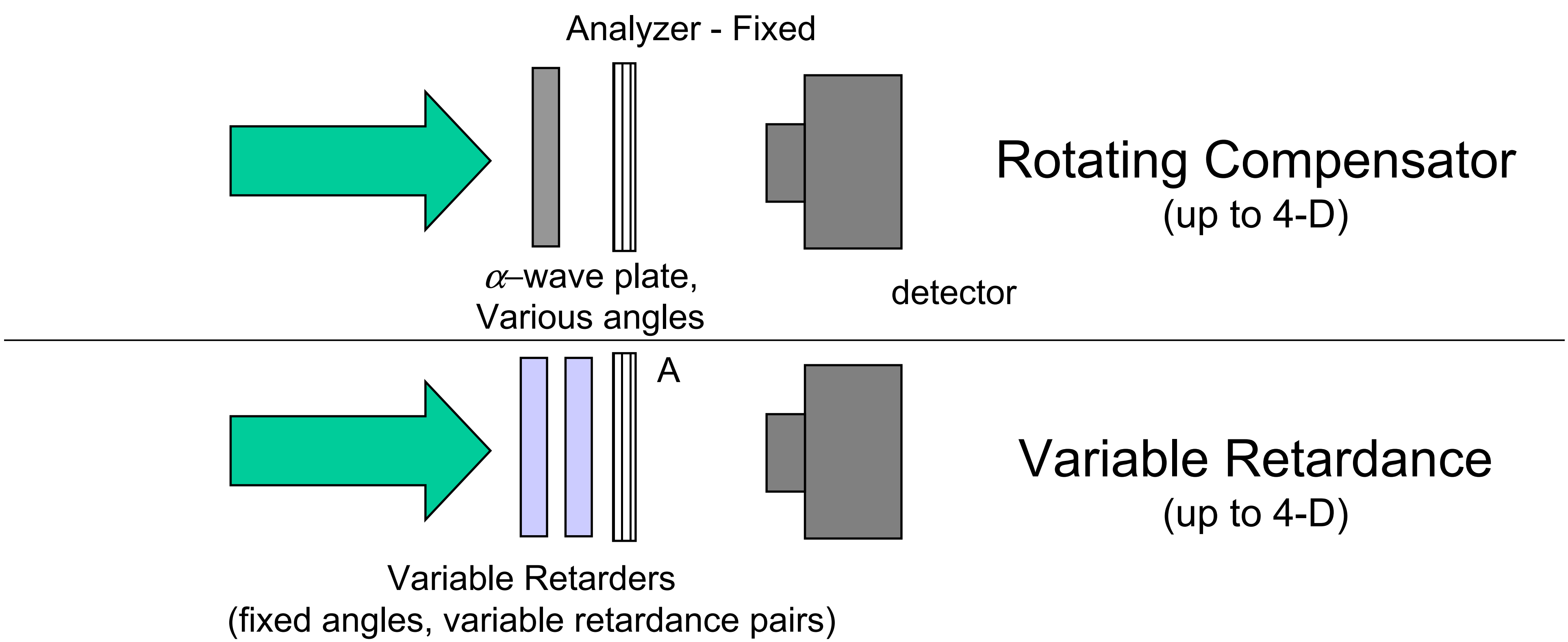
Robust Representations in Scattering Media

2-D

3-D



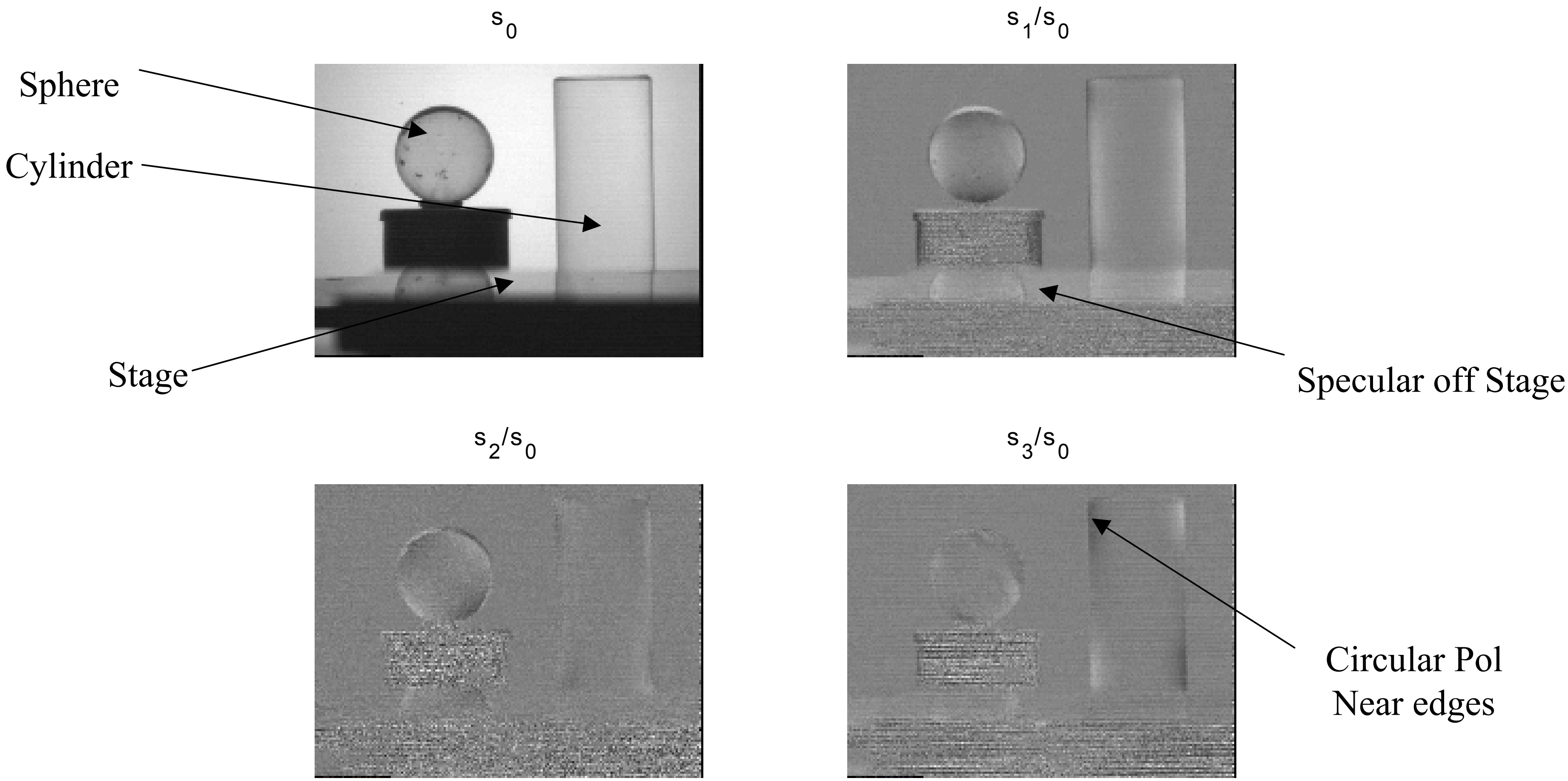
Full Stokes Vector Polarimeter Design



Data Collection can be either SERIAL or PARALLEL

Polarimetric images of sphere and cylinder

Variable Retardance Polarimetry



Tradeoffs for 4-D Polarimetry

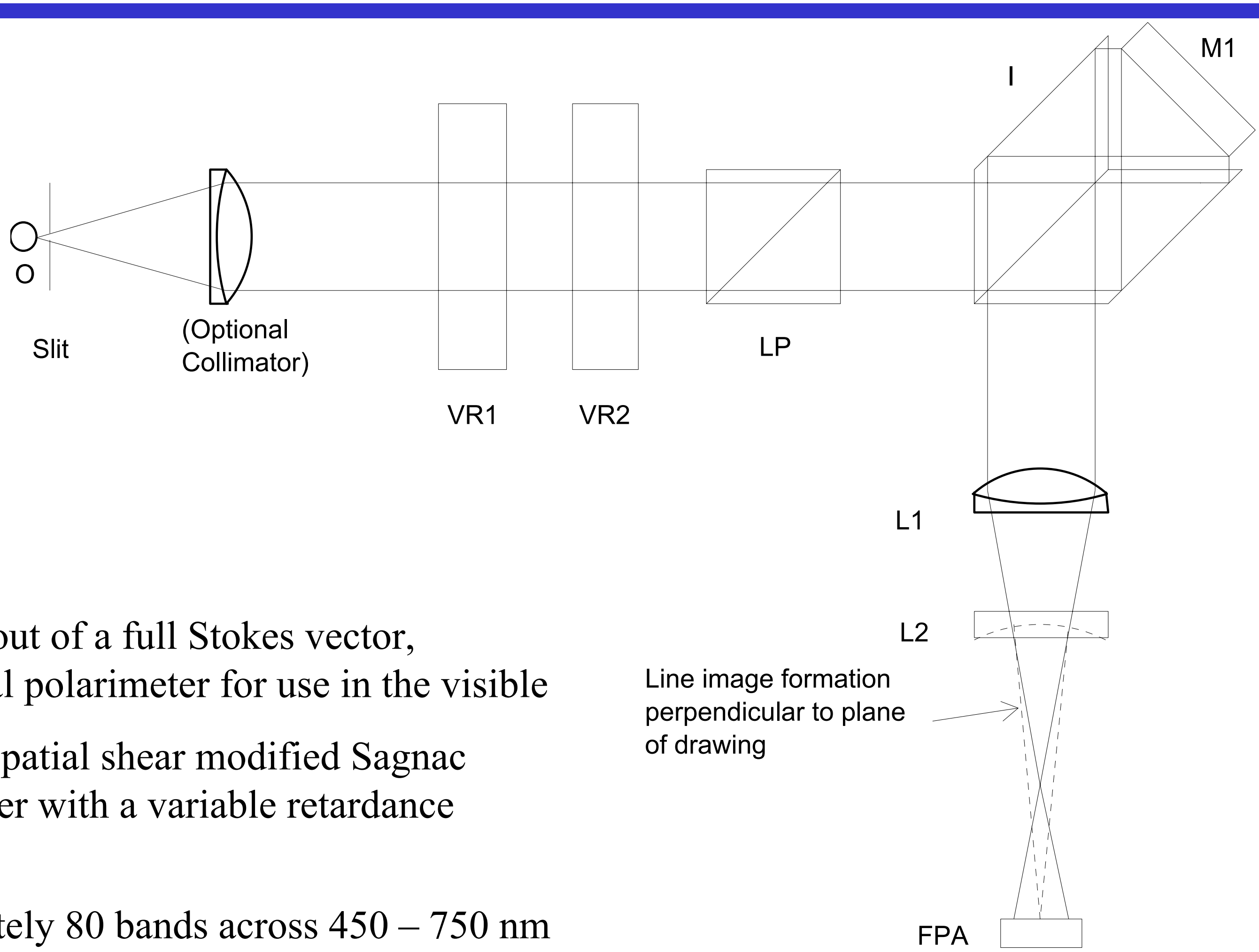
pros

- Provides full Stokes Vector Information
- No polarization blindness

cons

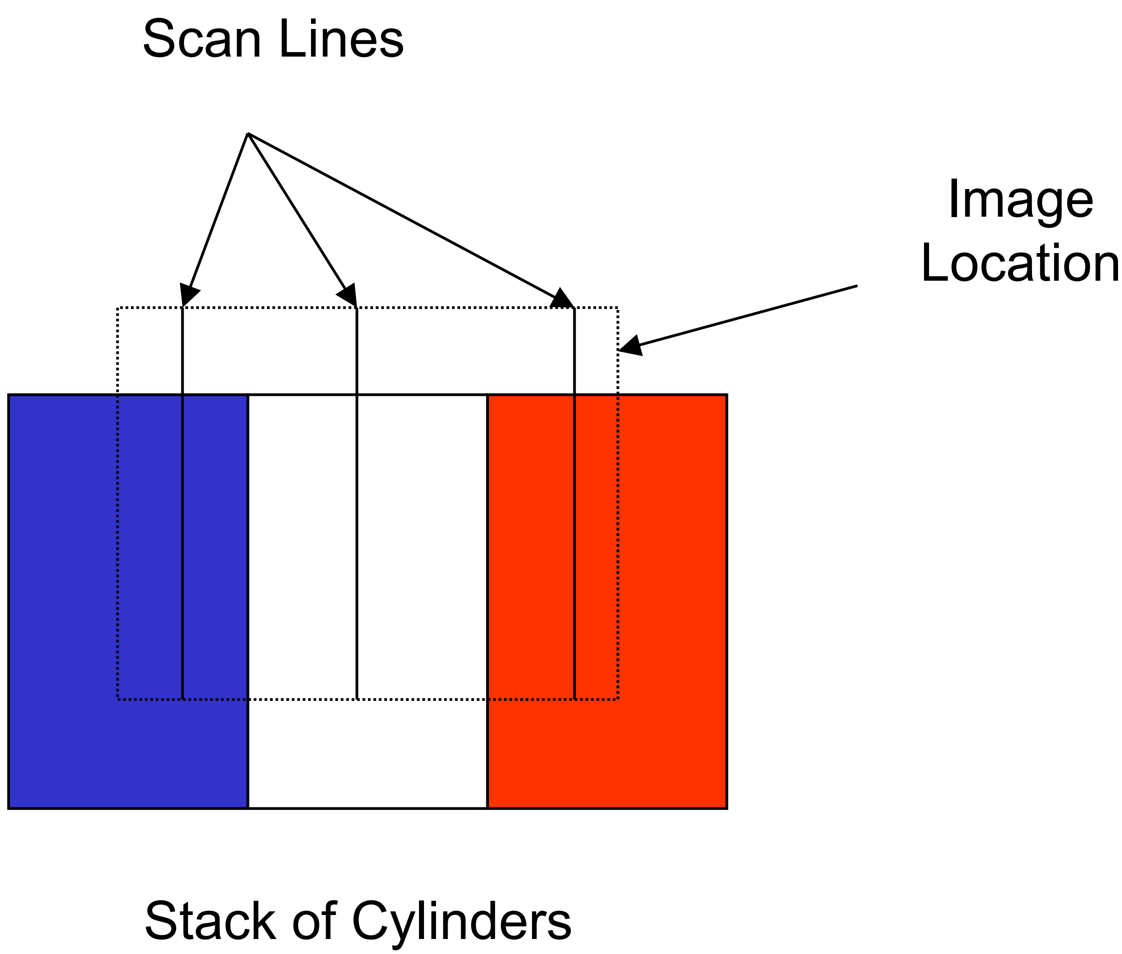
- Must collect at least 4 images (registration, spatiotemporal resolution)
- Requires circular polarization optics (expensive, difficult)

And What About Spectropolarimetry?

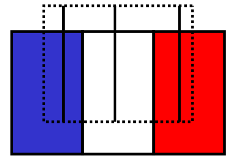


- Optical layout of a full Stokes vector, hyperspectral polarimeter for use in the visible
- Coupled a spatial shear modified Sagnac interferometer with a variable retardance polarimeter
- Approximately 80 bands across 450 – 750 nm

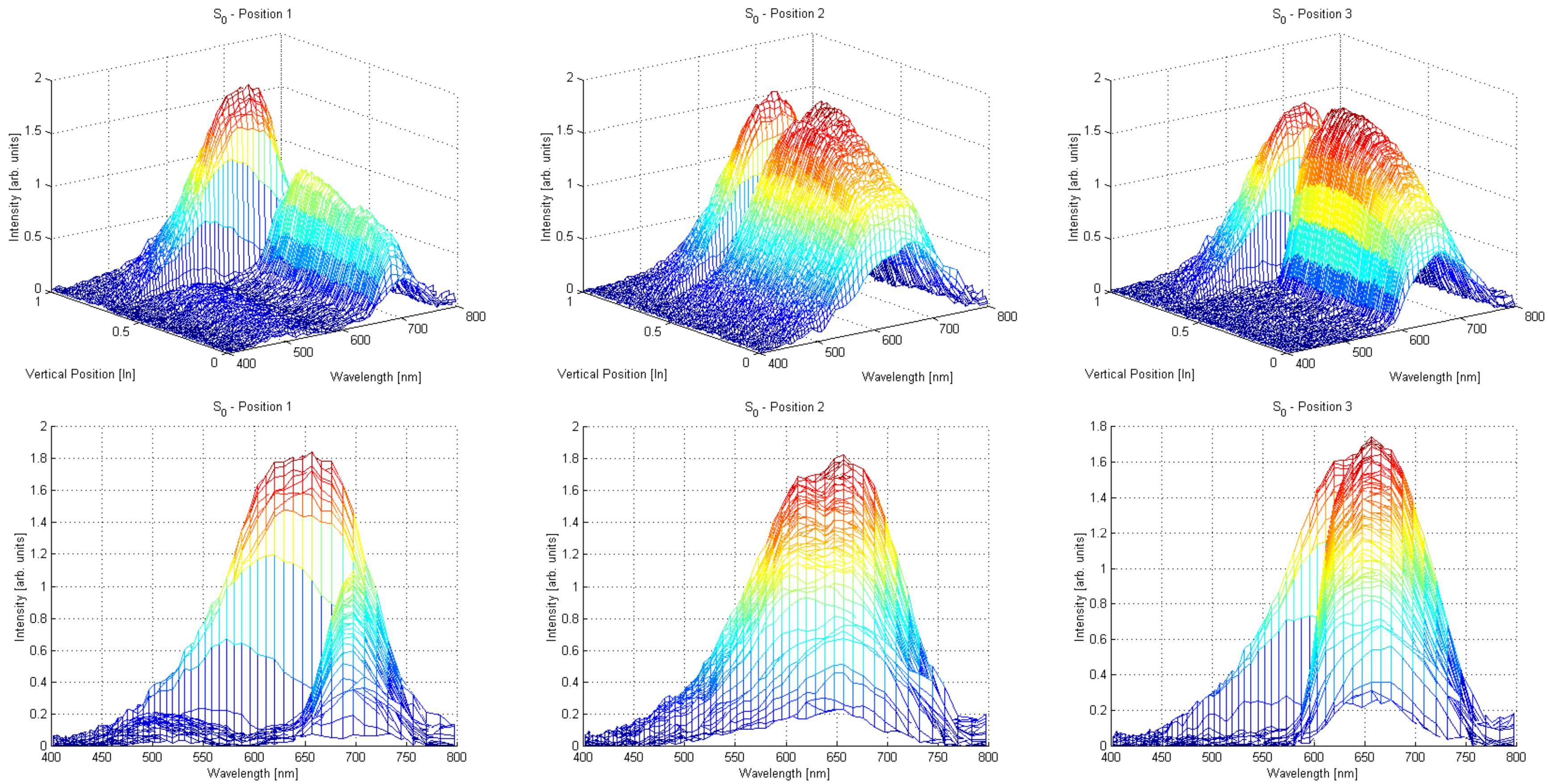
Experimental Images



Spatio-Spectral s_0 “Images”
Stack of Cylinders

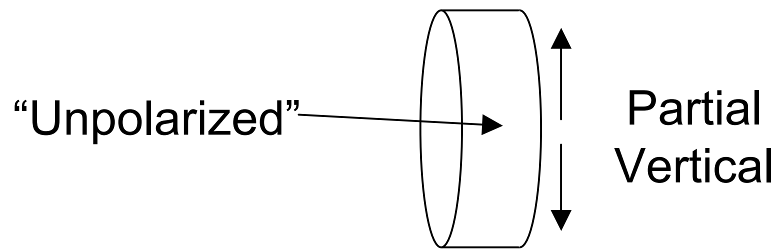


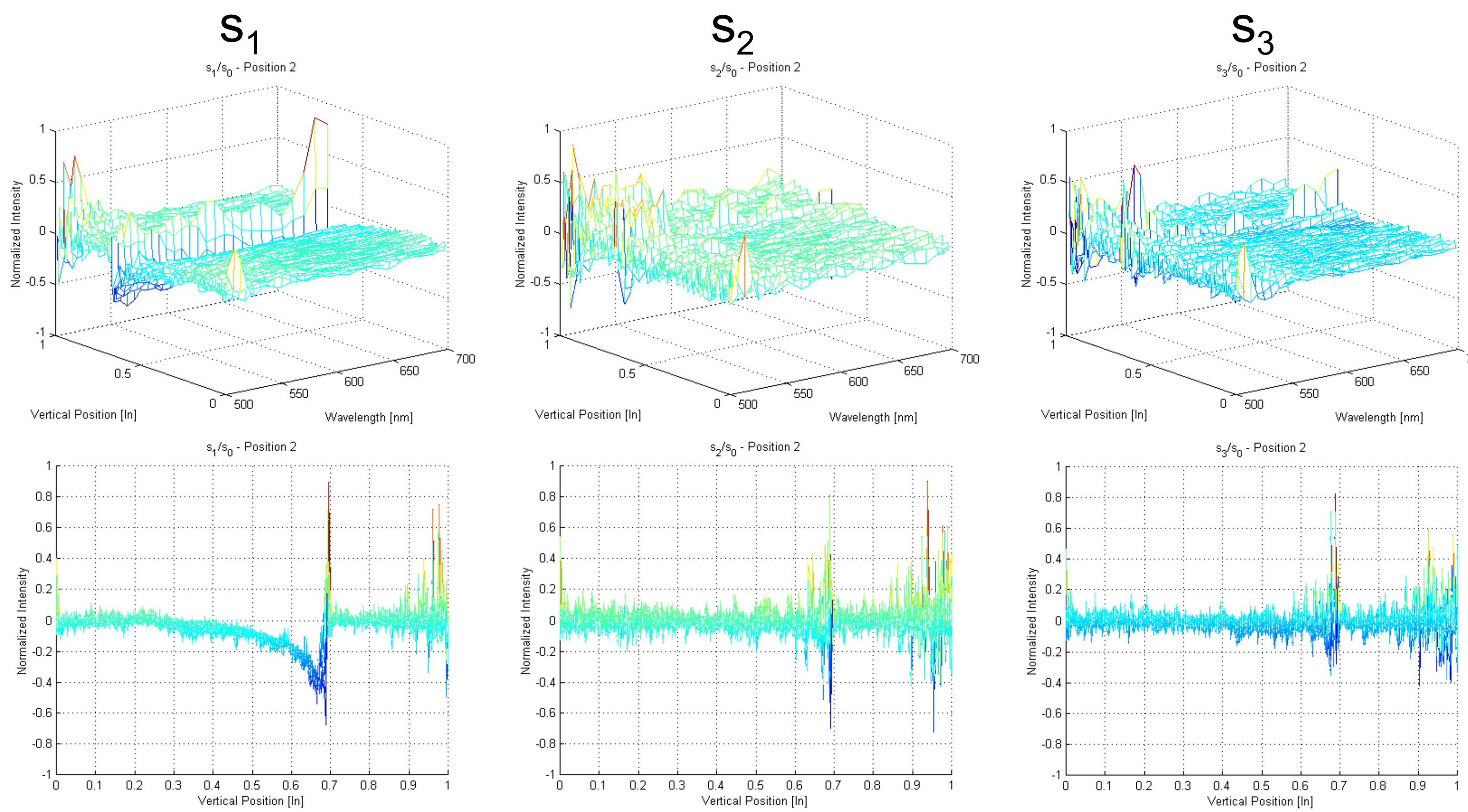
Blue Clear Red



Spatio-Spectral Stokes "Images"

Clear Cylinder





Tradeoffs for Spectropolarimetry

pros

- Provides Stokes vector information *at all wavelengths*
- Can calibrate out spectral dependence of optics
- Can be used as a spectrometer

cons

- Huge data storage and alignment issues
- Requires circular polarization optics (expensive, difficult)
- Major spatio-temporal resolution bottleneck
- Extremely low optical throughput
- Little or no evidence for highly spectrally resolved polarization information

Active Polarimetry

pros

- Can use polarization even when signature is depolarizing
- Can use in any wavelength regime (radar, lidar, etc.)
- Provides up to 16 dimensional information
- Can control illumination to maximize utility

cons

- System complexity
- Very low spatiotemporal resolution
- Difficult to do "broadband"
- Provides up to 16 dimensional information

Polarimeter Optimization

- There is an optimum configuration for *every* 2-D, 3-D, and 4-D polarimeter design, as well as active systems
- Depends on the strategy used and the number of measurement made
- Improper design of system can provide unnecessarily low SNR and oversensitivity to optical calibration issues

How Do We Detect Stokes Vector?

- Problem: Optical detectors are typically photon counters – Generally Pol-insensitive
  - We can only measure s_0!

- Solution: Design an optical system that modifies s_0 based on the input polarization
  - Infer $s_0 - s_3$ from intensity measurements

Polarimetric analysis – Variable Retardance

The Stokes vector of the emergent light is

$$\mathbf{S}_o = \mathbf{M}_{LP}\left(\theta\right)\mathbf{M}_{VR}\left(\phi_2,\delta_2\right)\mathbf{M}_{VR}\left(\phi_1,\delta_1\right)\mathbf{S}_i$$

With Intensity $I = \mathbf{M}_1{}^T \cdot \mathbf{S}_i$

Vary parameters to form a linear system:

$$\mathbf{I} = \mathbf{A}\cdot\mathbf{S}_i$$

Polarimetric analysis (cont.)

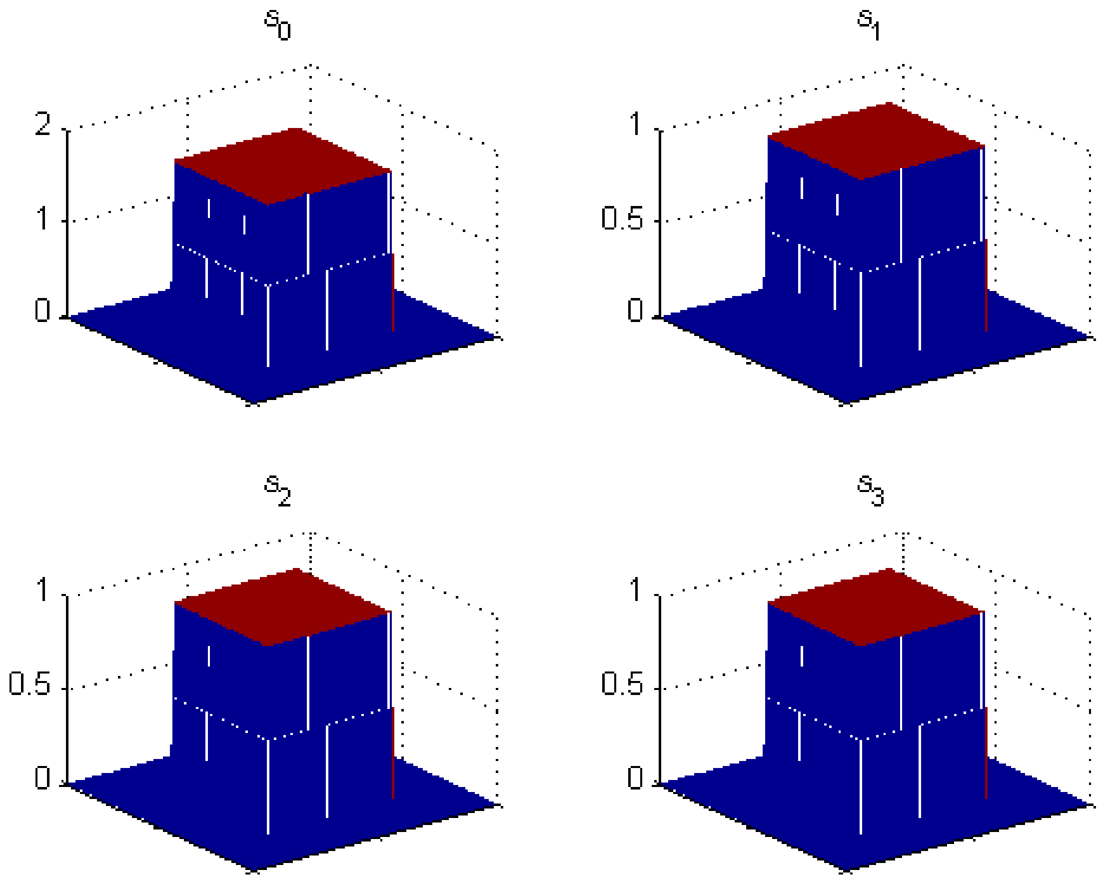
The input Stokes vector is obtained by inversion:

$$\mathbf{S}_i = \mathbf{A}^{-1} \cdot \mathbf{I} = \mathbf{B} \cdot \mathbf{I}$$

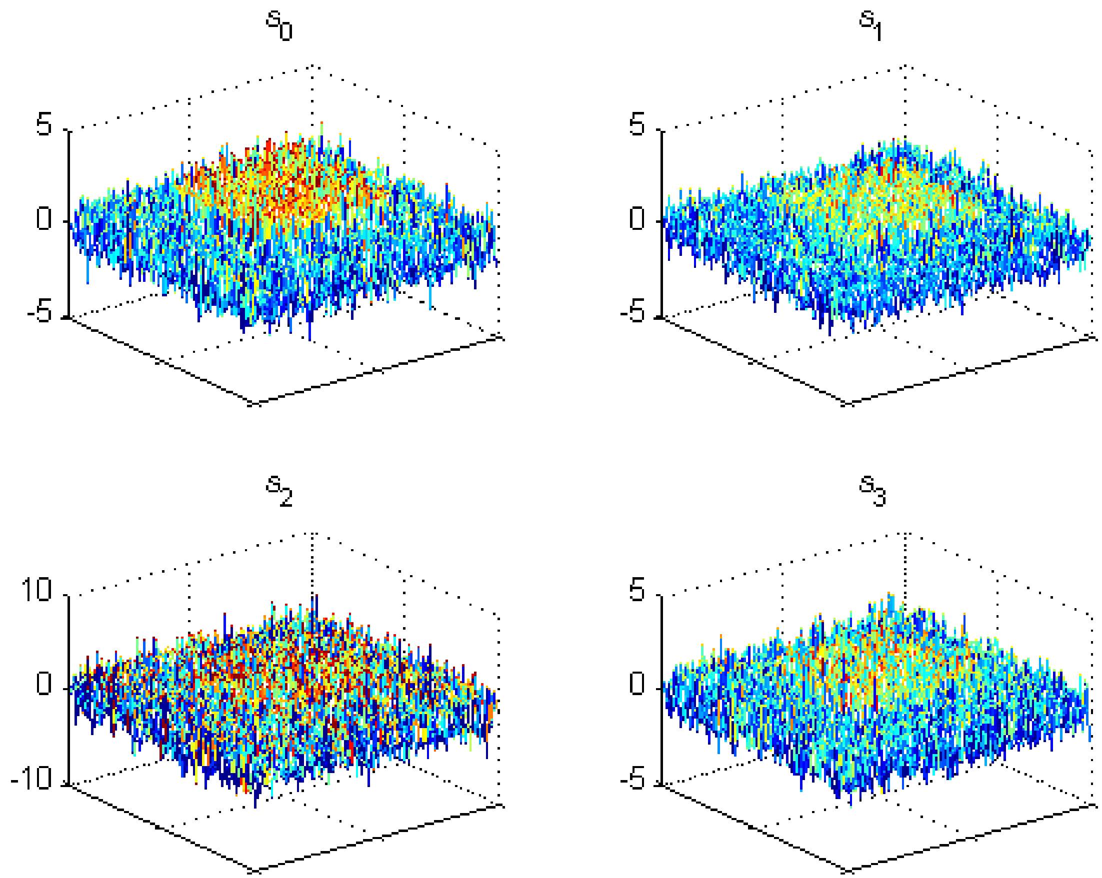
B is termed the "Synthesis Matrix" as it is used to reconstruct the Stokes Parameters

Simulated Images

$$\mathbf{S} = \begin{bmatrix} \sqrt{3} \\ 1 \\ 1 \\ 1 \end{bmatrix}$$



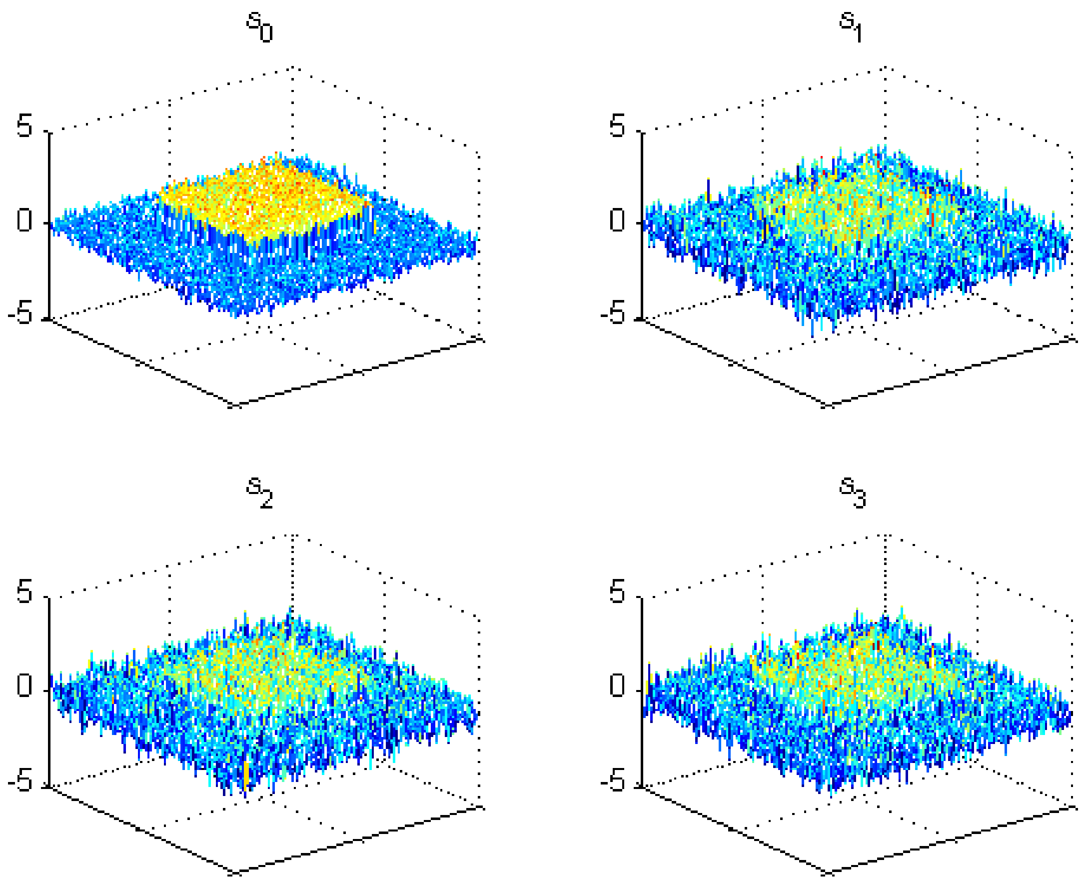
Simulated Images - Original Parameters



$$\langle \mathbf{S} \rangle = \begin{bmatrix} 1.74 \\ 0.99 \\ 0.98 \\ 1.00 \end{bmatrix}$$

$$\mathrm{var}(\mathbf{S}) = \begin{bmatrix} 0.59 \\ 0.43 \\ 1.93 \\ 0.60 \end{bmatrix}$$

Simulated Images - Optimized System

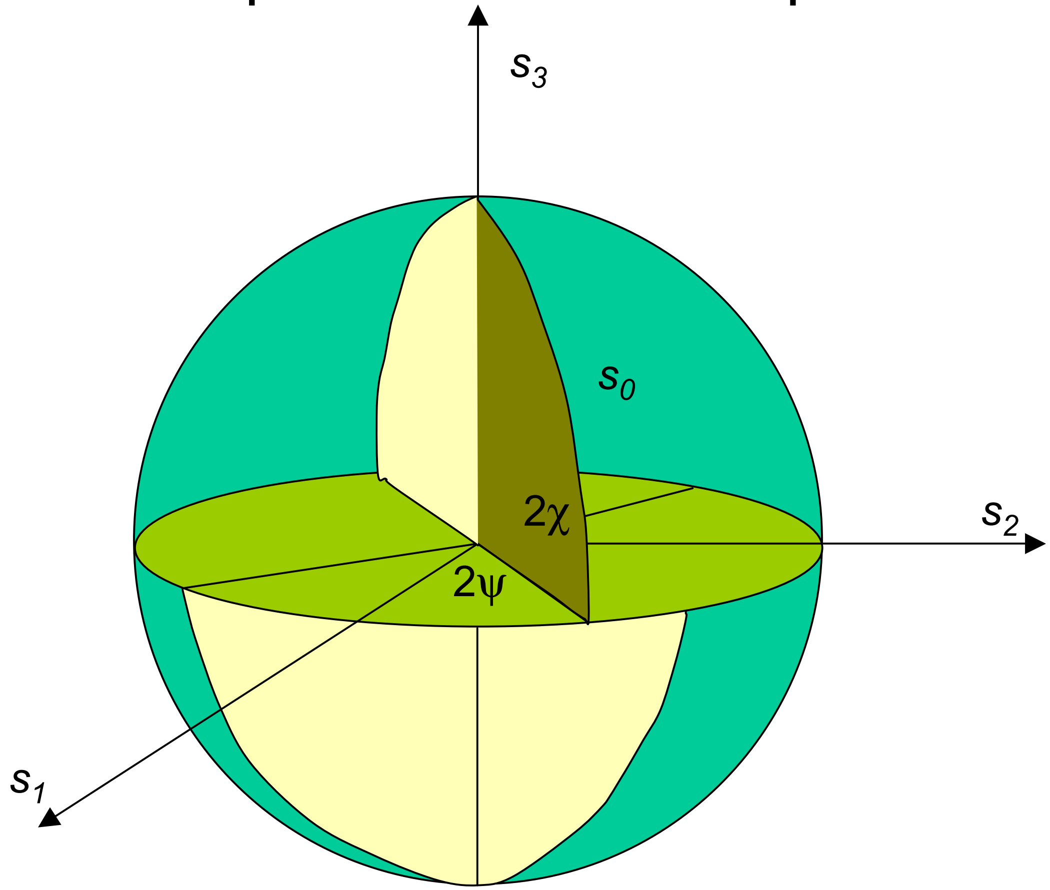


$$\langle \mathbf{S} \rangle = \begin{bmatrix} 1.73 \\ 1.00 \\ 1.00 \\ 1.00 \end{bmatrix}$$

$$\mathrm{var}(\mathbf{S}) = \begin{bmatrix} 0.10 \\ 0.29 \\ 0.31 \\ 0.30 \end{bmatrix}$$

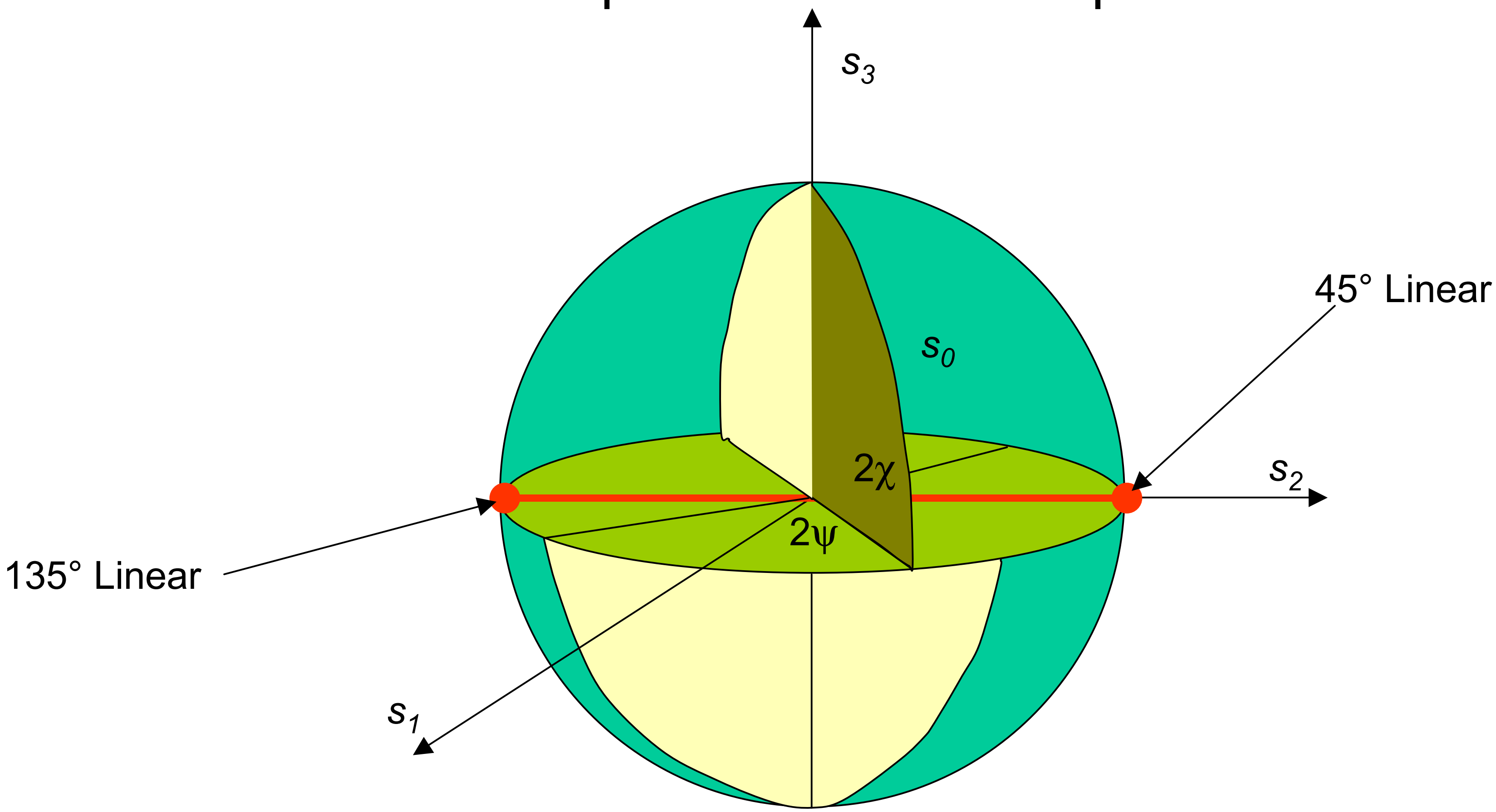
General Optimization

Maximum Possible Separation of Measurements
in Subspace of Poincaré Sphere



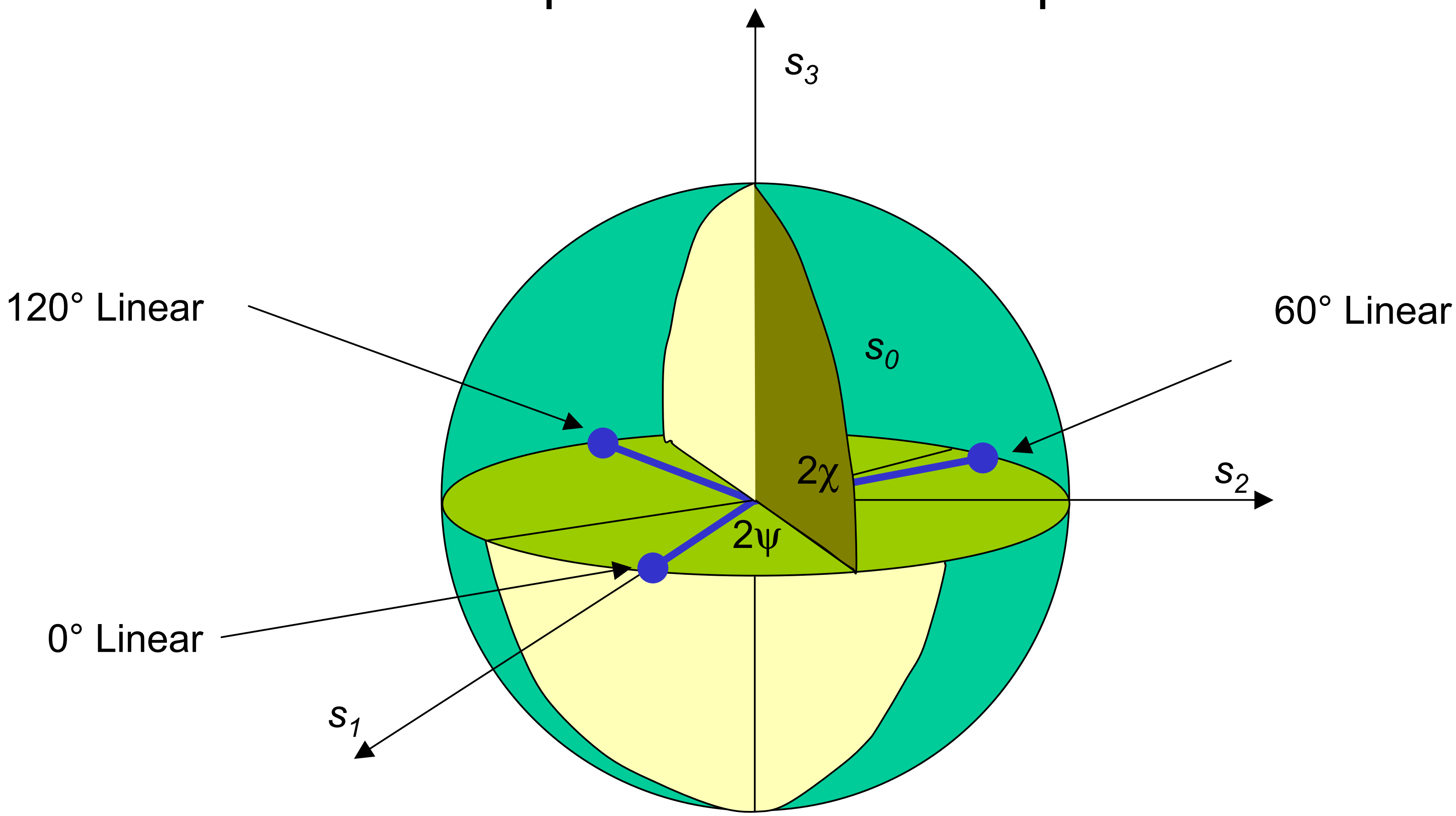
2-D Linear Polarization

Maximum Possible Separation of Measurements
in Subspace of Poincaré Sphere



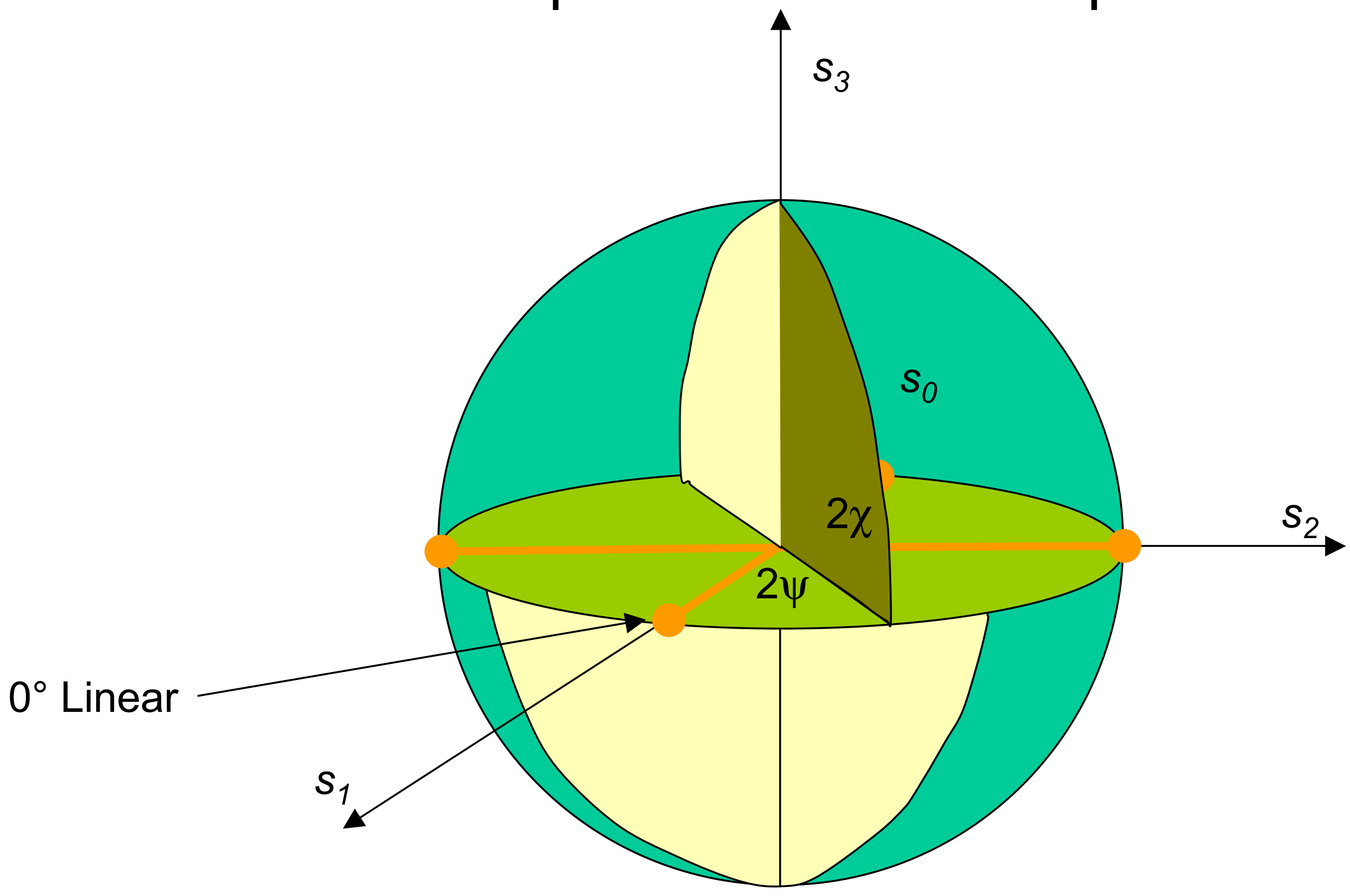
3-D Linear

Maximum Possible Separation of Measurements
in Subspace of Poincaré Sphere



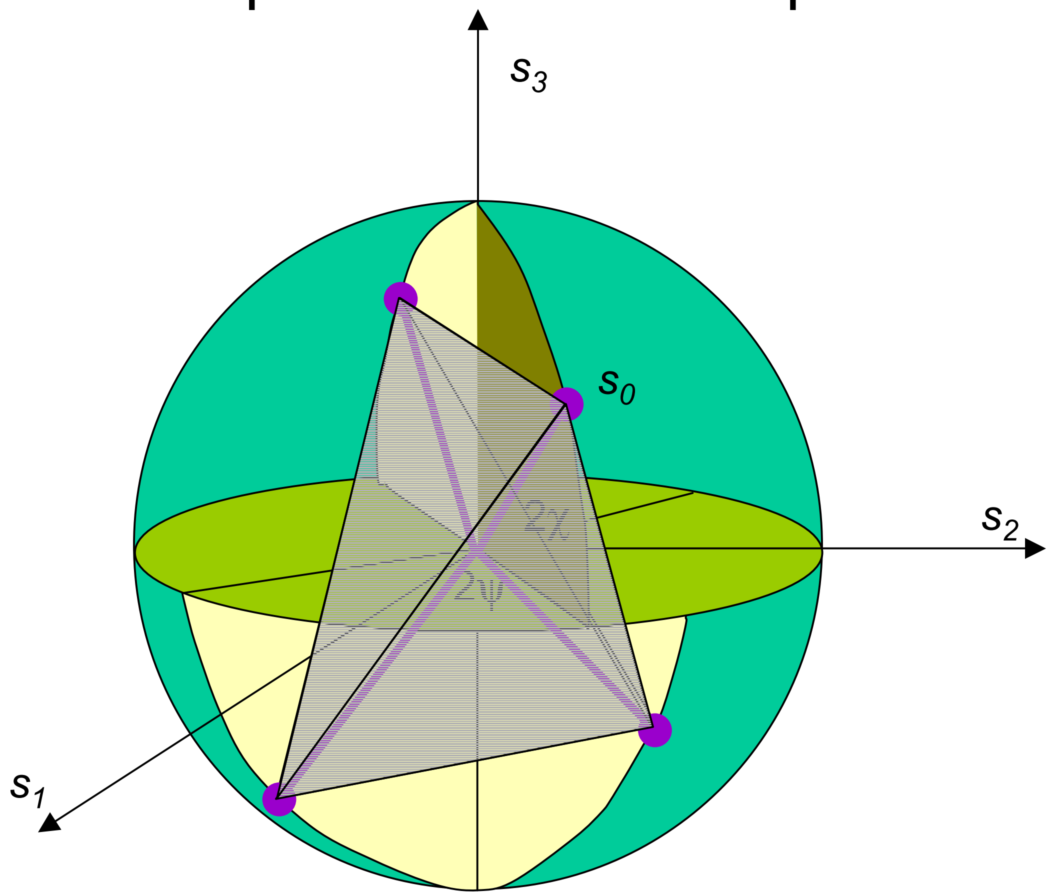
3-D Linear, 4 Measurements

Maximum Possible Separation of Measurements
in Subspace of Poincaré Sphere



4-D Stokes Vector

Maximum Possible Separation of Measurements
in Subspace of Poincaré Sphere



References for Optimization

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Design of Optimum Polarimeters

- The optimum set of parameters provides maximum information per measurement, i.e. these measurements are maximally decorrelated
- For Variable Retardance Polarimetry, a non-unique optimum parameter set will equalize the noise in the three Stokes images
- Rotating retarder systems - the optimum retardance is 132° - not 90°
- Rotating retarder systems – the optimum angles are at ±15.1°,±51.7°
- A new set of optimum settings must be computed for situations with a polarization bias (Tyo, *et al.*, 1996)
- In principle, such a set of optimum parameters exists for *any* polarimetry strategy
  - *N*-channel Linear Polarimetry (Tyo, 1998)
  - Variable Retardance Polarimetry (Tyo and Turner, 1999)
  - Rotating Compensator (Ambirajan and Look, 1995; Sweatt, *et al.*, 1999)